IN THE CLAIMS:

Claim 1 (currently amended): A method for identifying an object image that uses a density difference between a background image and an object image in a picture, said method comprising the steps of:

utilizing a method of obtaining a normal vector of the outline portion of an object image: by arranging points p at equal intervals on a picture, and for each respective point p, performing a fundamental wave Fourier transformation for each pixel value on the circumference of the circle which center is point p, and handling a phase obtained from said fundamental wave Fourier transformation as the normal vector of the outline portion of an object image;

arranging a Standard Object image on a picture in which an arrangement point, which is an arbitrary point on said picture that shows a background image, is used as a reference point;

determining a normal vector group on outline portions of said Standard Object image based upon density difference in said background image and said Standard Object image;

determining an angle information of respective normal vectors and determining a position information from said arrangement point to said respective normal vectors of said normal vector group;

storing said position information and angle information as standard data for said arrangement point;

determining, for a picture that shows an object image to be recognized, a normal vector group on outline portions of said object image based upon density difference in said object image and a background image;

determining a plurality of Answer point groups, that correspond to said arrangement points, from said normal vector group based upon said standard data; and

evaluating a focus point region formed by said Answer point group.

Claim 2 (currently amended): The method for identifying an object image according to Claim 1, wherein:

said Standard Object image is divided into two or more parts, and the same number of standard data is formed for each divided Standard Object image;

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an Answer point group is determined for each one of said standard data for the object image to be recognized, and [[MAP]] a plurality of screens in which said Answer point group are determined for every standard data are formed for the same number as said divided Standard Object image; and

said respective [[MAP]] plurality of screens are combined into an evaluation screen, and a focus point region formed by Answer point groups of said evaluation screen is evaluated.

Claim 3 (currently amended): The method for identifying an object image according to Claim 1 or Claim 2, wherein:

determining normal vector of background image and storing information of said normal vector group originating from said background image; and

wherein of said normal vector groups obtained from said picture that shows said Object image to be recognized, all of said normal vectors in vector groups which vector direction is unchangeable for a predetermined period of time are considered as being originated from said background image; and all of said normal vector groups, which are unchangeable for a long period of time, are removed, and said Answer point group is determined from remaining normal vector groups.

Claim 4 (cancelled).

Claim 5 (cancelled).

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